ABSTRACT OF THE DISCLOSURE

A servomotor driving controller capable of highly accurate machining, which prevents a quadrant projection upon change in the quadrant where machining is made. After the position deviation converges to zero by means of learning control, the velocity command or a difference between the velocity command and the commanded velocity which is the derivative of the position command is stored as velocity correction data. Until a predetermined time period elapses from when the sign of the position command is reversed, an amount of correction for each period of position loop processing is determined based on the correction data, and used to correct the velocity command.